

into $y^T u$:

$$p(t) \underset{\text{over in}}{=} y^T u = \dot{E}_c + \underbrace{v_{3x}^T i_{3x} + v_{2t}^T i_{2t}}_{\text{power into coupling circuit branches (which can be nonlinear)}}$$

if passive this should be **non-negative**

shows $y^T u - \dot{E}_c \geq 0$ definition of passivity used (for all t) in nonlinear control

∴ desire to set up semistate equations to handle nonlinear devices.

For capacitors $i_c = C \dot{v}_c$ assume they are in the tree

For input currents, J ; assume in links.

$$i_{2t} = g_{2t}(v_b) = g_{2t}(e^T v_t)$$

$$i_{3x} = g_{3x}(v_b) = g_{3x}(e^T v_t)$$

$x = \begin{bmatrix} v_c \\ v_{2t} \\ i_{3x} \\ J \end{bmatrix}$ for tree branches not with capacitor for links branches not current sources

$$i_b = J^T i_x + J_{\text{sources}}; \quad v_b = e^T v_t$$

$$= \begin{bmatrix} i_x \\ i_{2t} \\ i_{3x} \\ 0 \end{bmatrix} + \begin{bmatrix} 0 \\ 0 \\ 0 \\ J \end{bmatrix} = \begin{bmatrix} 1 & 0 \\ k_{11} & k_{12} \\ k_{21} & k_{22} \end{bmatrix} \begin{bmatrix} v_c \\ v_{2t} \end{bmatrix}$$

$$= \begin{bmatrix} -k_{11}^T & -k_{21}^T \\ -k_{12}^T & -k_{22}^T \\ 1_x \end{bmatrix} \begin{bmatrix} i_{3x} \\ J \end{bmatrix}$$

$$i_c = C \dot{v}_c = \begin{bmatrix} C & 0 & 0 & 0 \\ 0 & 0 & 0 & 0 \\ 0 & 0 & 0 & 0 \\ 0 & 0 & 0 & 0 \end{bmatrix} \begin{bmatrix} \dot{v}_c \\ \dot{v}_{2t} \\ \dot{i}_{3x} \\ \dot{J} \end{bmatrix} = \begin{bmatrix} 0 & 0 & -k_{11}^T & -k_{21}^T \\ 0 & 0 & +k_{12}^T & +k_{22}^T \\ 0 & 0 & -1 & 0 \\ 0 & 0 & 0 & -1 \end{bmatrix} x + \begin{bmatrix} 0 \\ g_{2t}(e^T v_t) \\ g_{3x}(e^T v_t) \\ 0 \end{bmatrix} + \begin{bmatrix} 0 \\ 0 \\ 0 \\ 1 \end{bmatrix} u$$

nonlinear dynamics in semistate form

$$E \dot{x} = A(x) + B u; \quad u = [0 \ 0 \ 0 \ J]^T$$

$y = C x$ ← after specifying an output in terms of voltages & currents in the circuit (all functions of tree voltage & link currents)

If have nonlinear capacitors (or inductors) need to transform via nonlinear non-dynamic circuits loaded by linear capacitors. also can do for time-varying. so get in general

$$E \dot{x} = A(x,t) + Bu$$

$$y = Cx$$